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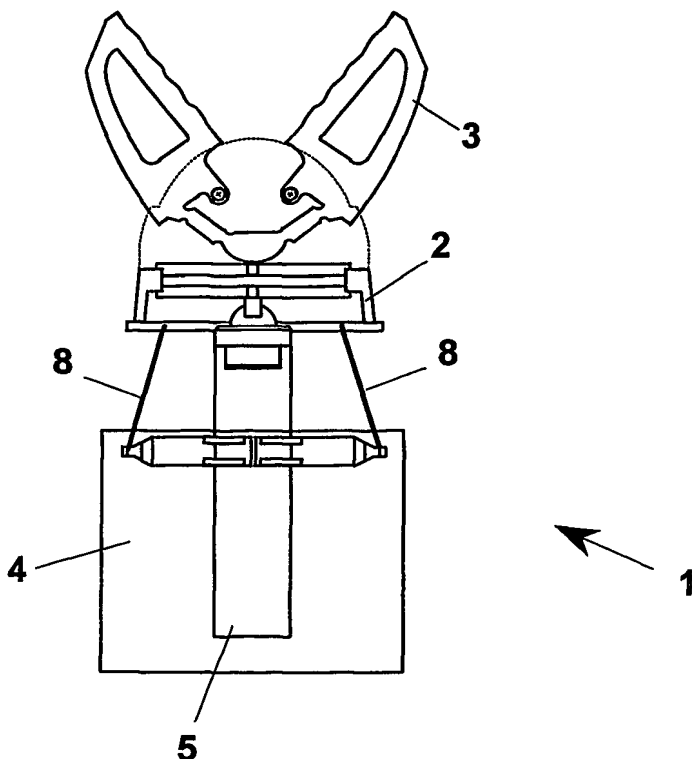
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- (54) Title: REMOTELY ACTUATED ROBOTIC WRIST



- (57) Abstract:** Remotely actuated robotic wrist for applications in the field of teleoperation, for example for miniminvasive surgical operations, comprising a distal element (3) mounted on a support (2) capable instantaneously to rotate with respect to a fixed member (5), for example by a ball joint (10) that allows three rotational degrees of freedom. In particular, the support (2) can be oriented with respect to the fixed member (5) with a redundant actuating system by arranging four forces in eccentric points, for example by means of tendons (8), and causing the rotation of the support (2) about the central post (5) by the ball joint (10). Alternatively, the support (2) can be oriented with respect to the fixed member (5) by a mechanism that reproduces the rolling of a mobile sphere, which belongs to the support, on a fixed sphere, integral to the fixed member.



SI, SK, TR), OAPI (BF, BJ, CF, CG, CI, CM, GA, GN, GQ, GW, ML, MR, NE, SN, TD, TG).

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